

WEST Search History

DATE: Saturday, August 11, 2007

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	<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L21	dynamics same model and L18	51
<input type="checkbox"/>	L20	dyanamics and L18	0
<input type="checkbox"/>	L19	dyanamics same model and L18	0
<input type="checkbox"/>	L18	L16 and L17	141
<input type="checkbox"/>	L17	movement or trajectory and L16	2459930
<input type="checkbox"/>	L16	floor and zmp and L3	150
<input type="checkbox"/>	L15	floor and zmp and L14	0
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<input type="checkbox"/>	L13	motion pattern and L11	2
<input type="checkbox"/>	L12	motion pattern and stor\$3 and L11	0
<input type="checkbox"/>	L11	freedom and L10	5
<input type="checkbox"/>	L10	L8 and L9	6
<input type="checkbox"/>	L9	L8 and gait or gate	1122553
<input type="checkbox"/>	L8	('6580969' '6493606' '6463356' '6289265' '6243623' '5872893' '5841258' '5838130' '5594644'	18
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<input type="checkbox"/>	L5	(legged robot or pet robot or humanoid near10 robot) motion and pattern and L4	0
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	(700/245 700/246 700/251 700/253 700/260 700/261 or 318/568.1 318/568.12 318/568.16		
<input type="checkbox"/>	L3	318/568.17 318/568.2 or 901/1 901/9 901/46 or 180/8.1 180/8.6 180/65.1 or 701/23 or	9436
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<input type="checkbox"/>	L2	6580969.pn.	2
<input type="checkbox"/>	L1	11/456454	1

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Key: IEEE JNL = IEEE Journal or Magazine, IEE JNL = IEE Journal or Magazine, IEEE CNF = IEEE Conference, IEE CNF = IEE Conference, IEEE STD = IEEE Standard

1. **A novel gait generation for biped walking robots based on mechanical energy constraint**
Asano, F.; Yamakita, M.; Kamamichi, N.; Zhi-Wei Luo;
Robotics and Automation, IEEE Transactions on
Volume 20, Issue 3, June 2004 Page(s):565 - 573
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2. **Some extensions of passive walking formula to active biped robots**
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Volume 4, Apr 26-May 1, 2004 Page(s):3797 - 3802 Vol.4
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3. **Biped Gait Generation and Control Based on a Unified Property of Passive Dynamic Walking**
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4. **Adaptive gait algorithm for IWR biped robot**
Sun-Ho Lim; Jin-Geol Kim;
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21-24 Feb. 1995 Page(s):438 - 443 vol.1
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18-22 April 2005 Page(s):609 - 615
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7. **A new method of desired gait synthesis in biped robot**
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Intelligent Control and Automation, 2000. Proceedings of the 3rd World Congress on
Volume 2, 28 June-2 July 2000 Page(s):1300 - 1304 vol.2

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9. **Reinforcement learning method-based stable gait synthesis for biped robot**
Hu Lingyun; Sun Zengqi;
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Volume 2, 6-9 Dec. 2004 Page(s):1017 - 1022 Vol. 2
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10. **A New Humanoid Robot Gait Generation Based on Multiobjective Optimization**
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11. **Motion control strategy for humanoid robot MIH-1**
Jing Pan; Jianbo Su; Xusheng Lei; Feng Lan;
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12. **A novel gait generation for biped walking robots based on mechanical energy constraint**
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Volume 3, 30 Sept.-5 Oct. 2002 Page(s):2637 - 2644 vol.3
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13. **Unification of dynamic gait generation methods via variable virtual gravity and its control performance analysis**
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Volume 4, 28 Sept.-2 Oct. 2004 Page(s):3865 - 3870 vol.4
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